

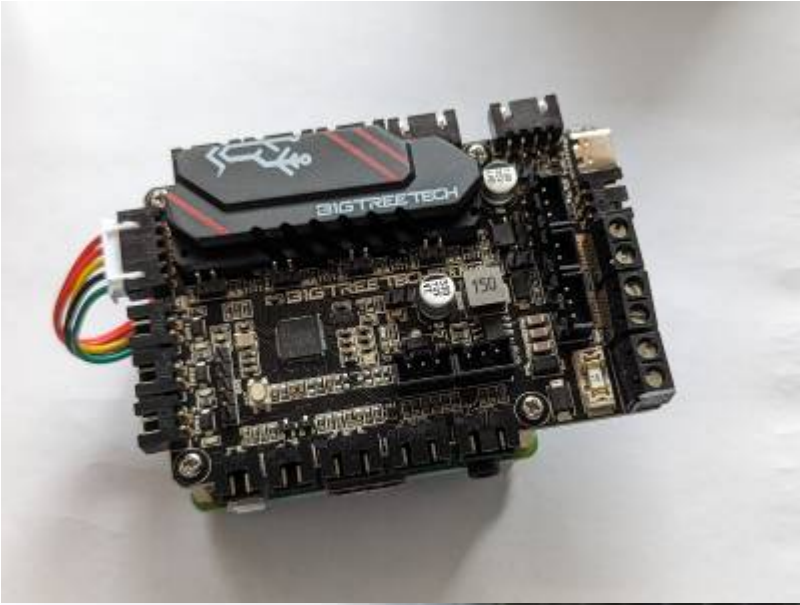
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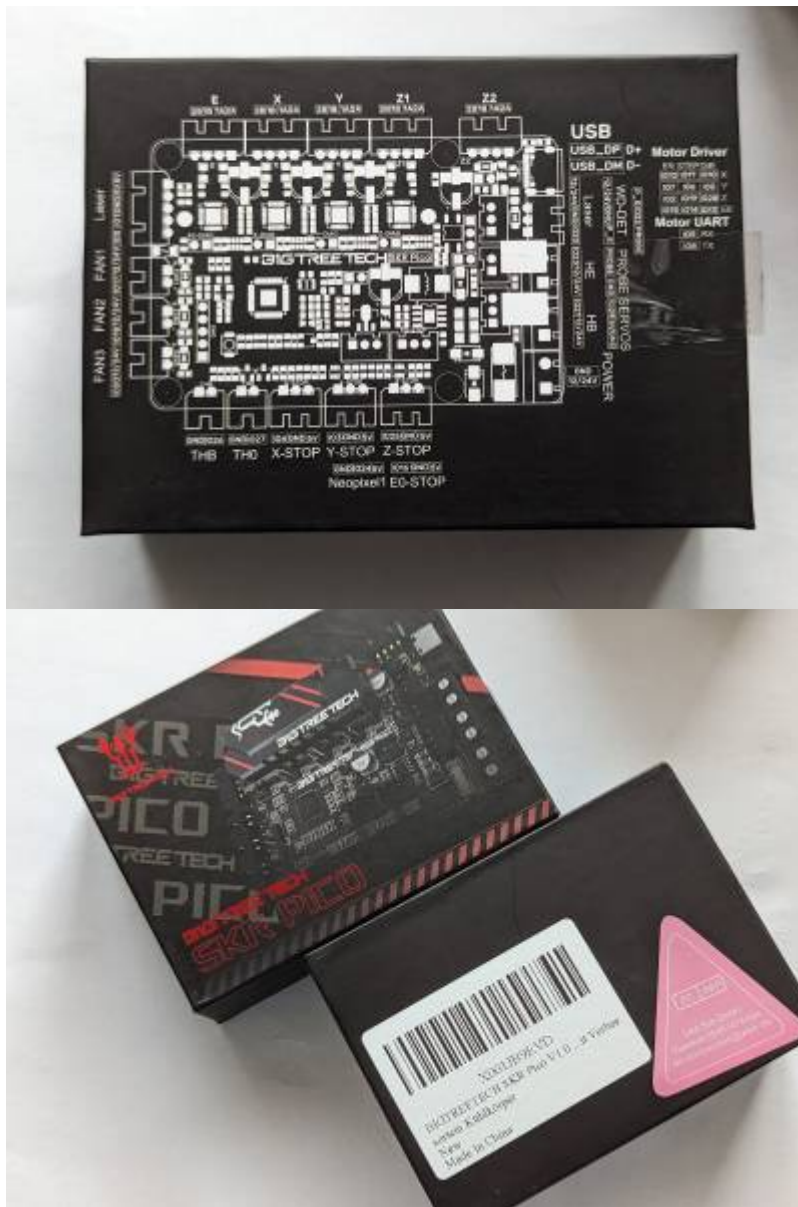
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Bigtreetech SKR Pico

- Das Board hat einen RPi Pico Core mit TMC2209 Treibern im Uart Modus.
- Es hat die Abmessungen eines RPi und würde prima mit einem RPi 3, 4 oder Zero 2 zusammen passen.
- Marlin: https://github.com/thinkyhead/Marlin/tree/bf2_wip_rp2040_skr_pico_PR
- Benötigt bei Entnahme von mehr als 0,9A pro Treiber aktive Kühlung.







Klipper Konfiguration für Ender 3 mit BL-Touch

```
[include fluidd.cfg]
#[include adxl.cfg]
[include kiah_macros.cfg]
[include macros.cfg]
[include start_end_macros.cfg]

[mcu]
serial: /dev/serial/by-id/usb-Klipper_rp2040_3672894954322E18-if00

[printer]
kinematics: cartesian
max_velocity: 300
max_accel: 3000
max_accel_to_decel: 1500
max_z_velocity: 5
square_corner_velocity: 5
```

```
max_z_accel: 100

[input_shaper]
shaper_freq_x: 98.8
shaper_type_x: mzv
shaper_freq_y: 40.8
shaper_type_y: mzv

[gcode_arcs]

[stepper_x]
step_pin: gpio11
dir_pin: !gpio10
enable_pin: !gpio12
microsteps: 16
full_steps_per_rotation: 200
rotation_distance: 40
endstop_pin: ^gpio4
# endstop_pin: tmc2209_stepper_x:virtual_endstop
# homing_retract_dist: 0
position_endstop: 0
position_max: 225
homing_speed: 100

[tmc2209 stepper_x]
uart_pin: gpio9
tx_pin: gpio8
uart_address: 0
run_current: 1
hold_current: 0.7
stealthchop_threshold: 0
# diag_pin: ^gpio4
# driver_SGTHRS: 100

[stepper_y]
step_pin: gpio6
dir_pin: !gpio5
enable_pin: !gpio7
microsteps: 16
full_steps_per_rotation: 200
rotation_distance: 40
endstop_pin: ^gpio3
# endstop_pin: tmc2209_stepper_y:virtual_endstop
# homing_retract_dist: 0
position_endstop: 0
position_max: 225
homing_speed: 100

[tmc2209 stepper_y]
```

```
uart_pin: gpio9
tx_pin: gpio8
uart_address: 2
run_current: 0.75
hold_current: 0.5
stealthchop_threshold: 0
diag_pin: ^gpio3
driver_SGTHRS: 100

[stepper_z]
step_pin: gpio19
dir_pin: gpio28
enable_pin: !gpio2
microsteps: 16
full_steps_per_rotation: 200
rotation_distance: 8
# endstop_pin: ^gpio25
endstop_pin:probe: z_virtual_endstop
position_min: -5
position_max: 255
homing_speed: 35

[tmc2209 stepper_z]
uart_pin: gpio9
tx_pin: gpio8
uart_address: 1
run_current: 0.7
hold_current: 0.5
stealthchop_threshold: 0

[extruder]
step_pin: gpio14
dir_pin: !gpio13
enable_pin: !gpio15
microsteps: 16
rotation_distance: 22.230
nozzle_diameter: 0.4
filament_diameter: 1.75
heater_pin: gpio23
sensor_type: EPCOS 100K B57560G104F
sensor_pin: gpio27
control = pid
pid_kp = 30.959
pid_ki = 1.433
pid_kd = 167.179
min_temp: 0
max_temp: 250
min_extrude_temp: 180
pressure_advance = 0.40
pressure_advance_smooth_time: 0.040
```

```
[tmc2209 extruder]
uart_pin: gpio9
tx_pin: gpio8
uart_address: 3
run_current: 0.7
hold_current: 0.5
stealthchop_threshold: 0

# [filament_switch_sensor runout_sensor]
# switch_pin: ^gpio16
# pause_on_runout: True

# [filament_motion_sensor smart_sensor]
# switch_pin: ^gpio16
# detection_length: 2.5

[heater_bed]
heater_pin: gpio24
sensor_type: EPCOS 100K B57560G104F
sensor_pin: gpio26
#control: pid
#pid_Kp=71.830
#pid_Ki=1.800
#pid_Kd=716.505
min_temp: 0
max_temp: 110

[fan]
pin: gpio17

[heater_fan hotend_fan]
pin: gpio18
heater: extruder
heater_temp: 50.0

[safe_z_home]
home_xy_position: 110, 110 # Change coordinates to the center of your print
bed
speed: 100
z_hop: 10 # Move up 10mm
z_hop_speed: 80

[bed_screws]
screw1: 30.5, 37
screw2: 30.5, 207
screw3: 204.5, 207
screw4: 204.5, 37
screw5: 110, 110
```



```
[bltouch]
sensor_pin: gpio22
control_pin: gpio29
#z_offset: 0.2
x_offset: -42
y_offset:0
samples: 2

[bed_mesh]
speed: 150
horizontal_move_z: 5
mesh_min: 20, 30
mesh_max: 170, 210
probe_count: 5, 3

[temperature_sensor Board_MCU]
sensor_type: temperature_mcu
min_temp: 0
max_temp: 100

[temperature_sensor Raspberry_Pi]
sensor_type: temperature_host
min_temp: 0
max_temp: 100

#[neopixel board_rgb]
#pin: gpio24
#chain_count: 1
#color_order: GRB
#initial_RED: 0
#initial_GREEN: 0.5
#initial_BLUE: 0 # Paste here and save your klipper configuration

### <----- SAVE_CONFIG ----->
### DO NOT EDIT THIS BLOCK OR BELOW. The contents are auto-generated.
###
### [bltouch]
### z_offset = 2.050
###
### [bed_mesh Magnet plate]
### version = 1
### points =
###     -0.326250, -0.450000, -0.507500, -0.567500, -0.586250
###     -0.361250, -0.488750, -0.567500, -0.561250, -0.490000
###     -0.351250, -0.462500, -0.497500, -0.502500, -0.466250
### tension = 0.2
### min_x = 20.0
### algo = lagrange
### y_count = 3
### mesh_y_pps = 2
```

```
### min_y = 30.0
### x_count = 5
### max_y = 210.0
### mesh_x_pps = 2
### max_x = 170.0
###
### [heater_bed]
### control = pid
### pid_kp = 74.810
### pid_ki = 1.827
### pid_kd = 765.872
###
### [bed_mesh default]
### version = 1
### points =
###     -0.012500, -0.151250, -0.202500, -0.211250, -0.173750
###     0.207500, 0.043750, -0.051250, -0.112500, -0.077500
###     0.441250, 0.253750, 0.107500, -0.008750, -0.052500
### tension = 0.2
### min_x = 20.0
### algo = lagrange
### y_count = 3
### mesh_y_pps = 2
### min_y = 30.0
### x_count = 5
### max_y = 210.0
### mesh_x_pps = 2
### max_x = 170.0
```

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